

Zymark Twister II



Manufacturer: Zymark Corporation
Model Number: Twister2
Web Address: www.zymark.com

Twister II microplate handler offers expanded capacity of up to 400 plates. It is designed to provide fast, reliable access to consumables used in "typical" microplate assays.

Robotic Arm: Commands

- ▶ **AboutInfo()** - Displays the Zymark Twister ICP version.
- ▶ **GripClose()** - Closes the gripper.
- ▶ **GripOpen()** - Opens the gripper.
- ▶ **GripMaterial()** - Closes the gripper to grab a resource (e.g. microplate).
- ▶ **FindMaterial()** - Lowers the arm vertically until it 'finds' a plate. The arm should be placed directly above the plate before invoking this command.
- ▶ **HomeAllAxes()** - Causes each axis to move to its home position.
- ▶ **CreatePosition(position)** - Creates a new position from the robot current location.

position	String	Specifies the position coordinate to be created.
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- ▶ **DeletePosition(position)** - Deletes the existing position.

position	String	Specifies the position coordinate to be deleted.
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- ▶ **MoveAbsolute(rotary, reach, vertical, wrist, track)** - Causes the robot to move to the absolute position specified by the axis values.

rotary	Float	Absolute position for the rotary axis. Range of values: - 39000 to 285000 .
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reach	Float	Absolute position for the reach axis. Range of values: -9300 to 215000 .
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vertical	Float	Absolute position for the vertical axis. Range of values: - 560300 to 500 .
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wrist	Float	Absolute position for the wrist axis. Range of values: - 110000 to 110000 .
track	Float	Absolute position for the track axis.

▶ **MoveRelative(rotary, reach, vertical, wrist, track)** - Causes the robot to move to the position relative to the last MoveAbsolute position or relative to the absolute position set by the SetAbs command.

rotary	Float	Relative position for the rotary axis.
reach	Float	Relative position for the reach axis.
vertical	Float	Relative position for the vertical axis.
wrist	Float	Relative position for the wrist axis.
track	Float	Relative position for the track axis.

▶ **MoveToPosition(position)** - Causes the robot to move to a named position, that has been previously taught.

position	String	Position for the move.
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▶ **SetAbs(position)** - Selects a named, previously taught, position to be the reference position for the next MoveRelative command.

position	String	Position to be referenced.
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▶ **SetSpeedAsPercentMax(speed)** - Sets the robotic arm speed.

speed	Integer	Percentage of the maximum speed. Range of values: 1 to 100 .
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Robotic Arm: Errors

🔥 **TwisterError(code, description)** - Error occurred during command execution.

code	Integer	Error code.
description	String	Error description.

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